

Amendments to the Abstract:

~~The invention relates to a~~ A method for calibration of a working point (TCP) for tools (13) on industrial robots (8) with a calibration device[[.]] (1), ~~comprising includes the use of~~ at least two light barriers with an azimuth angle (α) greater than zero at an angle to each other and intersecting at an intersection point. (R), ~~comprising~~ The method includes the steps: a) fixing set TCP positional coordinates for a set working point (TCP<SB>SOLL</SB>) for the tool (13), relative to a tool reference point (W) of the industrial robot (8) and a TCP coordinate system relative to the working point (TCP), b) moving the tool (13) ~~directly~~ to the set working point with relation to the TCP coordinate system through the light barriers, such that the tool tip of the tool (13), ~~corresponding to the working point (TCP),~~ interrupts the light [[E]] barriers[[.]], c) ~~recording actual TCP positional coordinates on interruption of a light barrier,~~ d) ~~determination of~~ determining the difference between the set TCP positional coordinates for the interruption of the light barriers for a set working point (TCP<SB>SOLL</SB>) and the corresponding recorded actual TCP positional coordinates for the actual working point (TCP<SB>IST</SB>), e) ~~calculation of deviation of~~ calculating the actual working point (TCP<SB>IST</SB>) from the set working point (TCP<SB>SOLL</SB>) for the number of levels ~~as defined by the~~ of light barriers from the differences and the known position and azimuth angles (a) of the light barriers.